Author Index to Volume 2

Arimoto, S.: See Miyazaki, F.

Benhabib, B., Goldenberg, A. A., and Fenton, R. G.: A Solution to the Inverse Kinematics of Redundant Manipulators, 373
Bhanu, B.: See Henderson, T.

Chiba, I.: See Hashimoto, M.

Dagalakis, N. G., and Myers, D. R.: Adjustment of Robot Joint Gears Using Encoder Velocity and Position Information, 229
—, and Myers, D. R.: A Technique for the Detection of Robot Joint Gear Tightness, 415
Driels, M. R., and Michael, K. M.: Evaluation of a Grey Scale Tactile Array Sensor Pad for Robotic Applications, 199

Fenton, R. G.: See Benhabib, B.
Fukada, T.: Flexibility Control of Elastic Robot Arms, 73
Fukushima, S.: See Sakawa, Y.
Furata, K., Kosuge, K., and Yamakita, M.: Trajectory Tracking Control of Robot Arms Using ORBIX, 89

Goldenberg, A. A.: See Benhabib, B.
—, and Kelly, A.: A Kinematics and Dynamics Simulation of the IBM-7565 Robot using AML, 353

Hansen, C.: See Henderson, T.
Hasegawa, J.: See Nakano, M.
Hashimoto, M., Takeda, M., Sagawa, H., Chiba, I., and Sato, Ki.: Application of Shape Memory Alloy to Robotic Actuators, 3
Hattori, K.: See Kinoshita, G.
Hayati, S., and Mirmirani, M: Improving the Absolute Positioning Accuracy of Robot Manipulators, 397
Hemami, H.: See Zhang, Y.F.
Henderson, T., Hansen, C., and Bhanu, B: The Specification of Distributed Sensing and Control, 387

Ichikawa, Y., and Ozaki, N.: Autonomous Mobile Robot, 135
Ikeda, T.: See Nakano, M.
Inari, T.: See Nakajima, T.
Inokuchi, S.: See Sato, Ko.
Ishibashi, K.: See Nagata, T.
Iwamoto, T., and Yamamoto, H.: Stairway Travel of a Mobile Robot with Terrain-Adaptable Crawler Mechanism, 125

Kakikura, M.: Research Activities on Robotics at the Electrotechnical Laboratory, 145
Kamei, M.: See Nakajima, T.
Kanayama, Y. and Yuta, S.: Computer Architecture for Intelligent Robots, 237
Kelly, A.: See Goldenberg, A. A.
Khosla, P. K., and Neuman, C. P.: Computational Requirements of Customized Newton-Euler Algorithms
Kinoshita, G., and Hattori, K.: Tactile Sensor Design and Tactile Sensing on 3-D Objects, 41
Koide, M.: See Nakano, M.
Kosuge, K.: See Furuta, K.
Kuno, T.: See Nakano, M.
Kyura, N.: See Nagamatsu, I.

Martin, H. L.: See Stroughton, R. S.
Matsuno, F.: See Sakawa, Y.

Melchior, K.: See Reuff, M.
Michael, K. M.: See Driels, M. R.
Mirmirani, M.: See Hayati, S.
Miyazaki, F., and Arimoto, S.: Sensory Feedback for Robot Manipulators, 53
Moribe, H.: See Nakano, M.
Murray, J. J.: See Neuman, C. P.
Myers, D. R.: See Dagalakis, N. G.

Nagamatsu, I., Tomiyama, T., Tanaka, M., and Kyura, N.: An Approach to Software Organization for Control of Industrial Robots, 265
Nagata, T., Tamura, H., and Ishibashi, K.: Detection of an Ellipse by Use of a Recursive Least-Squares Estimator, 163
Nakajima, T., Kamei, M., and Inari, T.: A Simplified Visual Inspection System Using a Personal Computer, 253
Nakano, M., Hasegawa, J., Kuno, T., Moribe, H., Ikeda, T., Koide, M., Shiroshita, O., and Sukigara, K.: TL-10: A Programming Language for Assembly Robots, 277
Neuman, C. P.: See Khosla, P. K.
—, and Murray, J. J.: Computational Robot Dynamics: Foundations and Applications, 425

Ozaki, N.: See Ichikawa, Y.

Reuff, M., and Melchior, K.: "BILDLIB": The Image Analysis Software at IPA, 179

Sagawa, H.: See Hashimoto, M.
Sakawa, Y., Matsuno, F., and Fukushima, S.: Modeling and Feedback Control of a Flexible Arm, 453
Sato, Ki.: See Hashimoto, M.
Sato, Ko., and Inokuchi, S.: Three-Dimensional Surface Measurement by Space Encoding Range Imaging, 27
Shiroshita, O.: See Nakano, M.
Slotine, J.J.E.: and Spong, M. W.: Robust Robot Control with Bounded Input Torques, 329
Spong, M. W.: See Slotine, J. J. E.
Stroughton, R. S., and Martin, H. L.: Duty-cycle Analysis of a Human Controlled Manipulator, 473
Sukigara, K.: See Nakano, M.

Takeda, M.: See Hashimoto, M.
Tamura, H.: See Nagata, T.
Tanaka, M. See Nagamatsu, I.
Togai, M.: Editorial, 1, 235
Tomiyama, T.: See Nagamatsu, I.

Yamakita, M.: See Furata, K.
Yamamoto, H.: See Iwamoto, T.
Yoshikawa, T.: Dynamic Manipulability of Robot Manipulators, 113
Yuta, S.: See Kanayama, Y.

Zhang, Y. F., and Hemami, H.: Mathematical Modeling of a Robot Collision with its Environment, 289